In the Specification:

(1) Please amendment paragraph 36 as follows:

In the third equation appearing in paragraph 36, please add the square symbol in the fourth square root in the equation to read as follows:

$$n_1 : n_2 : n_3 : n_4 = \sqrt{\left(x_n + \frac{y_n}{\tan\alpha_n} - W\right)^2 + L^2} : \sqrt{\left(x_n + \frac{y_n}{\tan\alpha_n} + W\right)^2 + L^2}$$

$$: \sqrt{\left(x_n + \frac{y_n}{\tan\alpha_n} - W\right)^2 + L^2} : \sqrt{\left(x_n + \frac{y_n}{\tan\alpha_n} + W\right)^2 + L^2}$$

(2) Please amend paragraph 37 as follows:

Please change "y_n" to "$L+y_n$" in the equations appearing in paragraph 37 to read as follows:

$$\alpha_1 = \tan^{-1}\left(\frac{2L}{x_n + \frac{L + y_n}{\tan\alpha_n} - W}\right)$$

$$\alpha_2 = \tan^{-1}\left(\frac{2L}{x_n + \frac{L + y_n}{\tan\alpha_n} + W}\right)$$

(3) Please amend paragraph 38 as follows:

Please change "y_n" to "$L+y_n$" in the equation appearing in paragraph 38 to read as follows:

$$n_1 : n_2 : n_3 : n_4 = \sqrt{\left(x_n + \frac{L + y_n}{\tan\alpha_n} - W\right)^2 + (2L)^2} : \sqrt{\left(x_n + \frac{L + y_n}{\tan\alpha_n} + W\right)^2 + (2L)^2}$$

$$: \left|x_n + \frac{L + y_n}{\tan\alpha_n} - W\right| : \left|x_n + \frac{L + y_n}{\tan\alpha_n} + W\right|$$

(4) Please amend paragraph 49 as follows:

Please change "l" to "1" in the equations appearing in paragraph 49 to read as follows:

$$\alpha_1 = -\alpha_3 = \tan^{-1}\left(\frac{1}{\frac{1}{\tan\alpha_0} - \frac{W}{L}}\right)$$

$$\alpha_2 = -\alpha_4 = \tan^{-1}\left(\frac{1}{\frac{1}{\tan\alpha_0} + \frac{W}{L}}\right)$$

(5) Please amendment paragraph 51 as follows:

Please change "l" to "1" in the second equation appearing in paragraph 51 to read as follows:

$$\alpha_2 = \tan^{-1}\left(\frac{1}{\frac{1}{\tan\alpha_0} + \frac{W}{2L}}\right)$$

(6) Please amend paragraph 161 as follows:

Please change "y_n1" to "y_n" in Equation (31) to read as follows:

$$n_1 : n_2 : n_3 : n_4 = \sqrt{\left(x_n + \frac{y_n}{\tan\alpha_n} - W\right)^2 + L^2} : \sqrt{\left(x_n + \frac{y_n}{\tan\alpha_n} + W\right)^2 + L^2}$$
$$: \sqrt{\left(x_n + \frac{y_n}{\tan\alpha_n} - W\right)^2 + L^2} : \sqrt{\left(x_n + \frac{y_n}{\tan\alpha_n} + W\right)^2 + L^2}$$

(7) Please amend paragraph 162 as follows:

Please delete "the above equation (28) .....(steering command value):" as noted below.

Please delete the equations (E11) and (E32) as noted below.

Please add equations $\tan\alpha_n = \frac{L+y_n}{R-x_n}$ and $R = \frac{L+y_n}{\tan\alpha_n} + x_n$ as noted below.

Please change "y_n" to "$L+y_n$" in Equations (32), (33) and (34) as noted below.

[00162] For steering mode M3, ~~the above equation (28) can be substituted in equations (E31), (E32) and (E34) to obtain the following equations (32), (33) and (34), and the wheel steering angles α_1, α_2, α_3, α_4, and rotation speeds n1, n2, n3 n4 can then be controlled based on α_n, the direction of travel of the point Pn (steering command value):~~

~~$\alpha_1 = \tan^{-1}\left(\frac{2L}{R-W}\right)$~~ ~~(E11)~~

$$\tan\alpha_n = \frac{L+y_n}{R-x_n}$$

$$R = \frac{L+y_n}{\tan\alpha_n} + x_n$$

$$\alpha_1 = \tan^{-1}\left(\frac{2L}{x_n + \frac{L+y_n}{\tan\alpha_n} - W}\right) \qquad \text{Equation (32)}$$

~~$\alpha_2 = \tan^{-1}\left(\frac{2L}{R+W}\right)$~~ ~~(E32)~~

$$\alpha_2 = \tan^{-1}\left(\frac{2L}{x_n + \frac{L+y_n}{\tan\alpha_n} + W}\right) \qquad \text{Equation (33)}$$

$\alpha_3 = \alpha_4 = 0$ Equation (E33)

$$n_1 : n_2 : n_3 : n_4 = \sqrt{\left(x_n + \frac{L+y_n}{\tan\alpha_n} - W\right)^2 + (2L)^2} : \sqrt{\left(x_n + \frac{L+y_n}{\tan\alpha_n} + W\right)^2 + (2L)^2}$$
$$: \left|x_n + \frac{L+y_n}{\tan\alpha_n} - W\right| : \left|x_n + \frac{L+y_n}{\tan\alpha_n} + W\right|$$

Equation (34)

In the Abstract:

Please amend Abstract of the Disclosure as follows:

In steering control for individually controlling wheel steering angles α_1, α_2, α_3, and α_4 of a vehicle in accordance with a condition equation for forming a prescribed mode, one of the condition equation variables is used as a steering command value S. In a process for changing the command value S from a value S_1 to a value S_2, for transitioning the steering angles α_1, α_2, α_3, α_4 from values $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S1}$ corresponding to the steering command value S_1, to values $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S2}$ corresponding to the steering command value S_2, the steering angles α_1, α_2, α_3, α_4 are changed toward incremental transition steering angles $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S1 + \Delta S}$ corresponding to a steering command value $(S_1 + \Delta S)$, which is the steering command value S_1 to which an incremental steering command value ΔS has been added. After the steering angles α_1, α_2, α_3, α_4 reach their incremental transition steering angles and steering angle conformance is detected, the angles are changed toward incremental transition steering angles $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S1 + n\Delta S}$ corresponding to a steering command value $(S_1 + n\Delta S)$, which is the steering command value to which an incremental steering command value ΔS has been added [n times] in succession. [[ł]]This is repeated as many times as required[[ł]]to change the steering angles α_1, α_2, α_3, α_4 from $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S1}$ to $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S2}$.